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by

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A Computer Checked Algebraic Verification of a Distributed Summation Algorithm

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Abstract

We present an algebraic verification of Segall's Propagation of Information with Feedback (PIF) algorithm and we report on the verification of the proof using the PVS system. This algorithm serves as a nice benchmark for verification exercises (see [2, 18, 9]). The verification is based on the methodology presented in [8] and demonstrates its suitability to deliver mechanically verifiable correctness proofs of highly nondeterministic distributed algorithms.

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1 Introduction

The applicability of formal methods for the specification and verification of distributed systems is still a much debated issue. For instance, in [2], Chou claims that there are still no formal methods to reason about distributed systems which are both practical and intuitive. In order to illustrate his opinion he introduces a variant of Segall's PIF (Propagation of Information with Feedback) algorithm [15] which he claims is difficult to prove correct formally. The purpose of this parallel algorithm is to collect the sum of values that are stored by processes which form the nodes of a finite, connected network. The algorithm is indeed an interesting benchmark problem for verification because it is highly parallel and non-deterministic. As such it has been treated in [2, 18, 9].

Here we present a verification of a distributed summation algorithm in μCRL , which is a process algebra which allows processes parameterised with data [7, 6]. The correctness of the algorithm is stated as a process equation (Theorem 3.5), the proof of which is a straightforward application of the methodology from [8], which is a combination of algebraic and assertional techniques. In [10] it is shown how proofs using this methodology can be proof-checked by computer using the proof checker COQ [3]. Here we have used similar techniques to check the verification using the theorem prover PVS from SRI [12, 13, 14, 16].

This paper is organised as follows. The algorithm is described informally in Section 2 and formally in Section 3. In Section 4, a linear process equation for the algorithm is given and it is proven that the resulting process does not admit infinite sequences of internal actions. Section 5 contains a set of invariants that characterise the reachable states of the algorithm. In Section 6, a state mapping is devised that relates configurations of the implementation to corresponding configurations of the specification. We prove that the state mapping is a branching bisimulation between the implementation and the specification. In section 7, we report on how we checked the proof in PVS. Section 8 contains a comparison of our proof with three other verifications of the summation μCRL algorithm [18, 2, 9]. Finally, Appendix A contains a short overview of the language μCRL and the methodology of [8].

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2 Description

The distributed summation algorithm does the following. Consider a set of processes that are connected via some network of bidirectional links (see e.g. Figure 1). We assume that all processes are connected, i.e. from each process we can reach any other process via one or more links. Each process contains some number, not known to other processes. The algorithm describes how to collect all numbers such that one designated (root) process can output the sum of these numbers. The major difficulty in doing so is to use each value in each process exactly once.

The algorithm is described as the parallel composition of a (finite) number of processes, indexed by natural numbers. Each process works in exactly the same way, except for the root

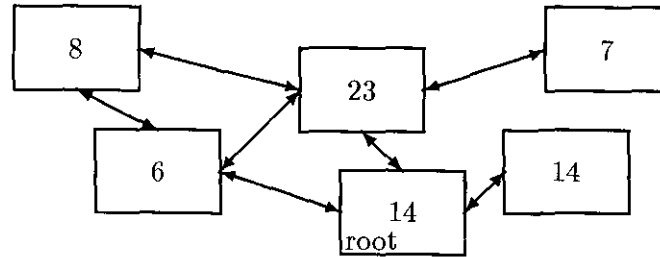


Figure 1: A set of distributed processes

process, which has number 0. This process differs from the other processes in the sense that initially it is already started, and when it has collected all sums of its neighbours, it issues a \overline{rep} message to indicate the total sum to the outside world, instead of a partial sum to a neighbour.

The overall idea behind the algorithm is that a minimal spanning tree over the links between the processes is constructed with as root the process 0. All partial sums are then sent via this spanning tree to the root. The difficulty of this protocol is that it is not a priori known how the spanning tree will look like. For every run of the algorithm nondeterministically a different spanning tree may be constructed.

Initially, a process is waiting for a *start* message from a neighbour. After it has received the first start message, the process is considered part of the spanning tree and the process by which it is started is called its *parent*. Thereafter it starts all its neighbours except its parent by a *start* message.

- Those neighbours that were not yet part of the minimal spanning tree will now become part of it with the current process as parent. Eventually, these neighbours will send a partial sum to the current process using an *answer* message.
- Those neighbours that were already part of the spanning tree ignore the start message. Note however that due to symmetry these processes will also send a start message to the current process.

So, a process gets from each neighbour except its parent either a partial sum or a start message. After having received these messages, it adds all received partial sums to its own value, and sends the result as a partial sum to its parent. Eventually, the root process 0 has received all partial sums, and it can report the total sum.

Theorem 3.5 says that this simple scheme is correct, i.e., if each process is connected to the root, processes do not have themselves as neighbours and the neighbour relation is symmetric, then the distributed summation algorithm computes the sum of the values of the individual processes. Note that if any of the stated conditions on the topology does not hold, the algorithm either deadlocks, not yielding a result, or it does not sum up all values.

3 Formal specification

In this section we will formalise the description given above and state the correctness criterion. The algorithm is described as the parallel composition of the algorithms for the individual

nodes in the network, which are described generically by means of a linear process equation. For a short introduction to the μCRL syntax of processes, we refer to Appendix A.

For the formal specification, we need the data type **Bool** of the booleans T and F and the usual operators \wedge , \vee , \rightarrow and \neg . We also use natural numbers \mathbb{N} with addition and (cut-off) subtraction.

The data type $nSet$ denotes finite sets of natural numbers. For such a set N we let $rem(i, N)$ represent the set N where element i has been removed. The function $size(N)$ yields the number of different elements in the set. We use \in and \notin to test membership of a set.

We also use lists of natural numbers $nList$ and lists of sets of natural numbers $SList$. Positions in lists are indexed by natural numbers, starting with index 0. For a list l , $l[i]$ is the element at position i of the list. We write $l[i] := t$ for the list l where t has been put at position i . As these data types are fairly standard, we have omitted their specification using abstract data types.

The processes of the network interact via matching actions st , \overline{st} (for *start*), ans , \overline{ans} (for *answer*) and the total sum is communicated using a \overline{rep} (for *report*) action. Although communication is synchronous, we think of the overbarred action as a send activity, and a non-overbarred action as the receiving activity. If an action a synchronises with an action \overline{a} , we call the resulting communication a^* . In μCRL we formally declare the actions and communications as follows.

act $st, \overline{st}, st^* : \mathbb{N} \times \mathbb{N}$ (parameters: destination, source)
 $ans, \overline{ans}, ans^* : \mathbb{N} \times \mathbb{N} \times \mathbb{N}$ (parameters: destination, source, value)
 $\overline{rep} : \mathbb{N}$ (parameter: value)

comm $st | \overline{st} = st^*$
 $ans | \overline{ans} = ans^*$

Definition 3.1 (*Processes*). Processes P are described by means of six parameters:

- i : the ID-number of the process.
- t : the *total sum* computed so far by the process. Initially, it contains the value that is contributed by process i to the total sum.
- N : a set of *neighbours* to which the process still needs to send a \overline{st} message.
- p : the index of the initiator, or *parent*, of the process. Variable p is also called the parent link of i .
- w : The number of st and ans messages that the process is still *waiting* for.
- s : the *state* the process is in. The process can be in three states, denoted by 0, 1, 2. If s equals 0, the process is in its initial state. If s equals 1, the process is active. If s equals 2, the process has finished and behaves as deadlock.

$$\begin{aligned}
P(i, t:\mathbb{N}, N:nSet, p, w:\mathbb{N}, s:\mathbb{N}) = \\
[s = 0] \Rightarrow \sum_{j:\mathbb{N}} st(i, j) P(i, t, rem(j, N), j, size(N)-1, 1) + \\
\sum_{j:\mathbb{N}} [j \in N \wedge s = 1] \Rightarrow \overline{st}(j, i) P(i, t, rem(j, N), p, w, s) + \\
\sum_{j,m:\mathbb{N}} [s = 1] \Rightarrow ans(i, j, m) P(i, t + m, N, p, w-1, s) + \\
\sum_{j:\mathbb{N}} [s = 1] \Rightarrow st(i, j) P(i, t, N, p, w-1, s) + \\
[i = 0 \wedge N = \emptyset \wedge w = 0 \wedge s = 1] \Rightarrow \overline{rep}(t) P(i, t, N, p, w, 2) + \\
[i \neq 0 \wedge N = \emptyset \wedge w = 0 \wedge s = 1] \Rightarrow \overline{ans}(p, i, t) P(i, t, N, p, w, 2)
\end{aligned}$$

□

In line 1 of P above, process i is in its initial state and an st message is received from some process j , upon which j is stored as the parent and s switches from 0 to 1, indicating that process i has become active. Since it makes no sense to send start messages to one's parent, j is removed from N . The counter w is initialised to the number of neighbours of i , not counting process j . In line 2, a \overline{st} message is sent to a neighbour j , which is thereupon removed from N . In line 3, a sum is received from some process j via an ans message containing the value m , which is added to t , the total sum computed by process i so far. The counter w is decreased. In line 4 a st message is received from neighbour j . The message is ignored, except that the counter w is decreased. In line 5 a $\overline{rep}(t)$ is sent (in case $i = 0$), when process 0 is active, there are no more ans or st messages to be received (formalised by the condition $w = 0$), and a \overline{st} message has been sent to all neighbours (formalised by the condition $N = \emptyset$). The status variable s becomes 2, indicating that process 0 is no longer active. Line 6 is as line 5 but for processes $i \neq 0$; now an \overline{ans} message is sent to parent p , containing the total sum t computed by process i .

Next, we define the parallel composition of $n + 1$ copies of the process P . The result can be viewed as a network of processes in the following way. Think of the $n + 1$ nodes of the network as items in a list of length $n + 1$. The neighbour relation is given by a list \mathbf{n} of length $n + 1$ of finite sets of natural numbers, with at each position i the set of neighbours of process i . The t -values of the processes are put in a list \mathbf{t} of length $n + 1$ of natural numbers, with at position i the t -value of process i . Similarly, the lists \mathbf{p} , \mathbf{w} , \mathbf{s} contain the values of the variables p , w and s of all processes, respectively.

Definition 3.2 (Parallel composition of processes).

$$\begin{aligned}
Impl(n:\mathbb{N}, \mathbf{t}:nList, \mathbf{n}:SList, \mathbf{p}:nList, \mathbf{w}:nList, \mathbf{s}:nList) = \\
P(0, \mathbf{t}[0], \mathbf{n}[0], \mathbf{p}[0], \mathbf{w}[0], \mathbf{s}[0]) \triangleleft n = 0 \triangleright \\
(P(n, \mathbf{t}[n], \mathbf{n}[n], \mathbf{p}[n], \mathbf{w}[n], \mathbf{s}[n]) \parallel Impl(n-1, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}))
\end{aligned}$$

□

Next, we formulate some requirements on the topology of the network.

Definition 3.3 (*Requirements for topology*). We fix a natural number n , denoting the number of non-root processes in the network, a list of natural numbers \mathbf{t}_0 of length $n + 1$, containing the initial t -values of each of the processes, and a list (of length $n + 1$) of sets of natural numbers \mathbf{n}_0 , containing for each process the id's its neighbours. We define $\text{goodtopology}(n, \mathbf{n}_0)$ as the conjunction of the following properties:

- No process has a link to itself: $\forall i \ i \notin \mathbf{n}_0[i]$;
- The neighbour relation is symmetric: $\forall i, j \leq n \ i \in \mathbf{n}_0[j] \leftrightarrow j \in \mathbf{n}_0[i]$;
- Every process $i \leq n$ is connected to process 0:
for all $i \leq n$ there exist $m \leq n$ and $i = i_0, \dots, i_m = 0$ such that, for all $0 \leq l < m$, $i_{l+1} \in \mathbf{n}_0[i_l]$.
- \mathbf{n}_0 only contains valid neighbours: $\forall i \forall j \leq n \ i \in \mathbf{n}_0[j] \rightarrow i \leq n$.

□

Definition 3.4 (*Distributed Summing Algorithm*). The distributed summation algorithm $D\text{Sum}$ is defined as Impl , initialised with, apart from n , \mathbf{t}_0 , and \mathbf{n}_0 , the following special values:

- \mathbf{p}_0 , a list of $n + 1$ 0's, saying that initially each process considers process 0 as its initiator.
- \mathbf{w}_0 , a list of length $n + 1$, with at each position i the size of the set $\mathbf{n}_0[i]$. Thus, initially every process expects a message from all its neighbours.
- \mathbf{s}_0 , a list of length $n + 1$, with in the first position a 1, to indicate that process 0 is active, and at the remaining n positions a 0, to indicate that all other processes are still sleeping.

We leave it to the reader to devise algebraic specifications of these lists. We put

$$D\text{Sum}(n, \mathbf{t}_0, \mathbf{n}_0) = \text{Impl}(n, \mathbf{t}_0, \mathbf{n}_0, \mathbf{p}_0, \mathbf{w}_0, \mathbf{s}_0)$$

□

The theorem below states correctness of the summation algorithm. It says that in a topology as described above, the distributed summation algorithm correctly reports the sum of all values in the processes and halts. The right hand side mentions a function sum , which sums up the numbers in a list of natural numbers.

The remainder of this paper is devoted to proving this theorem; it is repeated and proved as Theorem 6.3.

Theorem 3.5.

$$\begin{aligned}
& L\text{-Impl}(n:\mathbb{N}, \mathbf{t}:nList, \mathbf{n}:SList, \mathbf{p}, \mathbf{w}:nList, \mathbf{s}:nList) = \\
& \quad [\mathbf{n}[0] = \emptyset \wedge \mathbf{w}[0] = 0 \wedge \mathbf{s}[0] = 1] \Rightarrow \\
& \quad \quad \overline{\tau} \overline{ep}(\mathbf{t}[0]) L\text{-Impl}(\mathbf{s}[0] := 2) \quad + \\
& \quad \sum_{i,j:\mathbb{N}} [\mathbf{s}[i] = 0 \wedge i \in \mathbf{n}[j] \wedge \mathbf{s}[j] = 1 \wedge i \neq j \wedge i \leq n \wedge j \leq n] \Rightarrow \\
& \quad \quad \tau L\text{-Impl}(\mathbf{n}[j] := \text{rem}(i, \mathbf{n}[j]), \\
& \quad \quad \quad \mathbf{n}[i] := \text{rem}(j, \mathbf{n}[i]), \\
& \quad \quad \quad \mathbf{p}[i] := j, \\
& \quad \quad \quad \mathbf{w}[i] := \text{size}(\mathbf{n}[i]) - 1, \\
& \quad \quad \quad \mathbf{s}[i] := 1) \quad + \\
& \quad \sum_{i,j:\mathbb{N}} [\mathbf{s}[i] = 1 \wedge i \in \mathbf{n}[j] \wedge \mathbf{s}[j] = 1 \wedge i \neq j \wedge i \leq n \wedge j \leq n] \Rightarrow \\
& \quad \quad \tau L\text{-Impl}(\mathbf{n}[j] := \text{rem}(i, \mathbf{n}[j]), \\
& \quad \quad \quad \mathbf{w}[i] := \mathbf{w}[i] - 1) \quad + \\
& \quad \sum_{j:\mathbb{N}} [\mathbf{n}[j] = \emptyset \wedge \mathbf{w}[j] = 0 \wedge \mathbf{s}[j] = 1 \wedge \mathbf{s}[\mathbf{p}[j]] = 1 \wedge \\
& \quad \quad j \neq 0 \wedge j \neq \mathbf{p}[j] \wedge j \leq n \wedge \mathbf{p}[j] \leq n] \Rightarrow \\
& \quad \quad \tau L\text{-Impl}(\mathbf{t}[\mathbf{p}[j]] := \mathbf{t}[\mathbf{p}[j]] + \mathbf{t}[j], \\
& \quad \quad \quad \mathbf{w}[\mathbf{p}[j]] := \mathbf{w}[\mathbf{p}[j]] - 1, \\
& \quad \quad \quad \mathbf{s}[j] := 2)
\end{aligned}$$

Table 1: Linearisation of the implementation

$$\text{goodtopology}(n, \mathbf{n}_0) \rightarrow \tau \tau_I \partial_H(DSum(n, \mathbf{t}_0, \mathbf{n}_0)) = \tau \overline{\tau} \overline{ep}(\text{sum}(\mathbf{t}_0)) \delta$$

where $I = \{st^*, ans^*\}$ and $H = \{st, ans, \overline{st}, \overline{ans}\}$. In the trivial case that process 0 has no neighbours, the τ 's at the left and right hand side of the equation may be omitted.

4 Linearisation

In Table 1, we define the process $L\text{-Impl}$, which in Lemma 4.1 is stated to be a convergent linearisation of $\tau_I \partial_H(\text{Impl}(n, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}))$. The first and second τ -actions originate from hiding the action st^* . The third τ -action comes from hiding ans^* . In the recursive calls of $L\text{-Impl}$ only the parameters that are changed are displayed.

Lemma 4.1.

1. $L\text{-Impl}$ in Table 1 is convergent, i.e. does not admit infinite τ -paths.
2. $\tau_I \partial_H(\text{Impl}(n, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})) = L\text{-Impl}(n, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$.

$$3. \tau_I \partial_H(DSum(n, t_0, n_0)) = L-Impl(n, t_0, n_0, p_0, w_0, s_0)$$

Proof.

1. At each τ -step, either a link in n is removed, or a process moves from state 1 to state 2. Hence, the sum of the number of links in n and the number of processes in state 0 or 1 strictly decreases with each τ -step.
2. This follows from Theorem 3.5 in [5] and application of τ_I and ∂_H .
3. By item 2.

□

5 Invariants

We provide a number of invariants of which most express that bookkeeping is done properly (see Appendix A for a precise definition of invariants). The most interesting are invariants 14, 15 and 16. The first of these three implies that from each process in state 1 process 0 is reachable in a finite number of steps by iteratively following parent links (i.e. following variable p). As each process has a unique parent, this is an alternative way of saying that the parent links constitute a tree structure with process 0 as root (and a self-loop at the root). Invariant 15 expresses that along each such path all processes are in state 1 too, meaning that they are willing to pass partial results along. Invariant 16 expresses that the total sum in the processes is maintained in the processes that are not in state 2. We will see that at a certain moment all processes, except process 0, are in state 2, which implies that at that moment the total sum is present in process 0.

The invariants mention the functions *Preach*, *starters*, *children*, and *sum_{0,1}*, which are defined first.

Definition 5.1. Let t, n, p, s be as in Definition 3.2.

- The function *Preach*(i, j, p, m) expresses that from process i process j can be reached by following the parent links in p . So *Preach*(i, j, p, m) holds if there exist $i = i_0, \dots, i_m = j$ such that, for all $0 \leq l < m$, $p[i_l] = i_{l+1}$.
- *starters*(i, n) is the number of sets L in n such that $i \in L$. Intuitively, *starters*(i, n) is the number of processes that still want to send a \bar{st} message to process i .
- *children*(i, p, s) is the number of processes $j \neq 0$ in the list p such that $p[j] = i$ and $s[j] = 1$. That is, *children*(i, p, s) is the number of active non-root processes that regard process i as their parent.
- *sum_{0,1}*(t, s) is the sum of the $t[i]$ -values of the processes i that are not yet finished, i.e. such that $s[i] = 0$ or $s[i] = 1$.

□

Theorem 5.2. *The following are invariants of $L\text{-Impl}(n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$. Here the universal quantification over i and j is left implicit. The conjunction of the invariants is written as $\text{Inv}(\mathbf{n}_0, \mathbf{t}_0, n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$. Note that the initial topology \mathbf{n}_0 and the initial distribution of values \mathbf{t}_0 are part of the invariant, although these are not a parameter of $L\text{-Impl}$.*

1. $s[i] \leq 2$.
2. $p[i] \leq n$.
3. $i \in \mathbf{n}[j] \rightarrow i \leq n$.
4. $i \notin \mathbf{n}[i]$.
5. $s[0] \neq 0$.
6. $p[0] = 0$.
7. $s[i] = 0 \wedge j \in \mathbf{n}[i] \rightarrow i \in \mathbf{n}[j]$.
8. $s[i] = 0 \wedge i \in \mathbf{n}[j] \rightarrow j \in \mathbf{n}[i]$.
9. $s[i] = 0 \rightarrow \mathbf{n}[i] = \mathbf{n}_0[i]$.
10. $s[i] = 2 \rightarrow \mathbf{w}[i] = 0 \wedge \mathbf{n}[i] = \emptyset$.
11. *If a process i is in state 0, then it can't be a parent:*
 $s[i] = 0 \rightarrow p[j] \neq i$.
12. $s[i] = 0 \rightarrow \mathbf{w}[i] = \text{starters}(i, \mathbf{n}) \wedge \text{starters}(i, \mathbf{n}) = \text{size}(\mathbf{n}[i]) \wedge \text{children}(i, \mathbf{p}, \mathbf{s}) = 0$.
13. *For every process i , $\mathbf{w}[i]$ records exactly the number of messages that are to be received. These can either be st messages, or ans messages:*
 $\mathbf{w}[i] = \text{starters}(i, \mathbf{n}) + \text{children}(i, \mathbf{p}, \mathbf{s})$.
14. *From every process i process 0 is reachable via parent links in a finite number of steps:*
 $\exists m \text{ Preach}(i, 0, \mathbf{p}, m)$.
15. *If a process i is in state 1, then its parent is also in state 1:*
 $s[i] = 1 \rightarrow s[p[i]] = 1$.
16. *As long as no \overline{rep} message has been issued by process 0 (i.e. $s[0] \neq 2$), the total sum (i.e. $\text{sum}(\mathbf{t}_0)$) is present in the processes that are in state 0 or 1:*
 $s[0] \neq 2 \rightarrow \text{sum}_{0,1}(\mathbf{t}, \mathbf{s}) = \text{sum}(\mathbf{t}_0)$.

Proof. The invariants 1 to 12 are easily checked (invariant 6 uses invariant 5). The invariant 13 uses invariants 4, 5, 6, 8 and 12. The invariant 14 uses invariant 11. The invariant 15 uses invariant 13. The last invariant can be proven on its own. \square

6 State mapping, focus points and final lemma

In order to apply the methodology from [8], we specify a linear process $L\text{-Spec}$ describing the specification.

proc $L\text{-Spec}(b : \text{Bool}) = [b] \Rightarrow \overline{\text{rep}}(\text{sum}(t_0)) L\text{-Spec}(\neg b)$

Clearly, $L\text{-Spec}(\top) = \overline{\text{rep}}(\text{sum}(t_0))\delta$.

Furthermore, we provide a *state mapping* h , that specifies how the control variable b of the specification $L\text{-Spec}$ is constructed out of the parameters $n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}$ of the implementation $L\text{-Impl}$. We put

$$h(n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) = (\mathbf{s}[0] = 1).$$

The intuition behind this definition is as follows. In a configuration s of $L\text{-Impl}$ that satisfies $\mathbf{s}[0] = 1$, $h(s)$ is \top (true), so $L\text{-Spec}$ can perform the $\overline{\text{rep}}$ -action, after which it halts. $L\text{-Impl}$ may not be able to perform a matching $\overline{\text{rep}}$ action directly, since the computation of the value to be reported has not yet finished (i.e., $\mathbf{n}[0] \neq \emptyset$ or $\mathbf{w}[0] \neq 0$). However, using the fact that $L\text{-Impl}$ is convergent, we see that after a finite number of internal τ -steps a configuration s' is reached where no τ -step is enabled, $\mathbf{s}[0]$ is still 1 (h will be invariant under the τ -steps), but also $\mathbf{n}[0] = \emptyset$ and $\mathbf{w}[0] = 0$. So the $\overline{\text{rep}}$ -action can be performed (with the correct value), after which $L\text{-Impl}$ halts. Conversely, it is easy to verify that if in configuration s $L\text{-Impl}$ can perform the $\overline{\text{rep}}$ action, then $\mathbf{s}[0] = 1$, so in configuration $h(s)$ the control variable $b = h(s)$ of $L\text{-Spec}$ has the value \top and the specification $L\text{-Spec}$ can perform the $\overline{\text{rep}}$ -action (with corresponding value). From these observations it will follow that h is indeed a branching bisimulation function.

We formalise this intuitive argument, using a *focus condition*, which is a formula that characterises the configurations of $L\text{-Impl}$ in which no τ -step is enabled. (These configurations are so-called *focus points*). Such a formula is extracted from the equation characterising $L\text{-Impl}$ (see Table 1) by negating the guards that enable τ -steps in $L\text{-Impl}$. As an optimisation, we have put the first two negated guards together, and have restricted the focus condition to configurations satisfying the invariant.

$$\begin{aligned} FC(n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) &= \forall i, j \leq n \\ &(\mathbf{s}[i] = 2 \vee i \notin \mathbf{n}[j] \vee \mathbf{s}[j] \neq 1 \vee i = j) \wedge \\ &(\mathbf{n}[j] \neq \emptyset \vee \mathbf{w}[j] > 0 \vee \mathbf{s}[j] \neq 1 \vee \mathbf{s}[\mathbf{p}[j]] \neq 1 \vee j = 0) \end{aligned}$$

We distinguish two kinds of focus points of the distributed summation algorithm. One is the set of configurations where the algorithm has reported the sum and is terminated, so $\mathbf{s}[0] = 2$. The other one contains the configuration s' mentioned above and is characterised by $\mathbf{s}[0] = 1$. At that moment the correct sum should be reported. Items 1 and 2 of the lemma below say that all conditions in the process $L\text{-Impl}$ for issuing a $\overline{\text{rep}}$ action are satisfied; so reporting is possible. Item 3 says that in such a case, all other processes are in state 2. Hence, using invariant 16 (i.e., $\mathbf{s}[0] \neq 2 \rightarrow \text{sum}_{0,1}(t, \mathbf{s}) = \text{sum}(t_0)$) we may conclude that the total sum is indeed collected in process 0, i.e. process 0 reports the correct sum.

Lemma 6.1. *Inv*($\mathbf{n}_0, t_0, n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}$) and $\mathbf{s}[0] = 1$ together imply

1. $FC(n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) \wedge \mathbf{s}[i] = 1 \rightarrow \mathbf{n}[i] = \emptyset$

2. $FC(n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) \rightarrow \mathbf{w}[0] = 0$.
3. $goodtopology(n, \mathbf{n}_0) \wedge \mathbf{w}[0] = 0 \wedge i \neq 0 \rightarrow \mathbf{s}[i] = 2$.

Proof.

1. Towards a contradiction, assume there exists a process i such that $\mathbf{s}[i] = 1$ and $\mathbf{n}[i] \neq \emptyset$, say $j \in \mathbf{n}[i]$. By invariant 4 we have $j \neq i$. By the first part of $FC(n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$, $\mathbf{s}[j] = 2$. By invariant 10, $\mathbf{w}[j] = 0$, contradicting invariant 13 (remember that $j \in \mathbf{n}[i]$).
2. In order to derive a contradiction, assume that $\mathbf{w}[0] > 0$. For arbitrary m , we construct a sequence of $m + 1$ processes $0 = i_0, i_1, \dots, i_m$ such that for all $0 \leq l \leq m$, we have $\mathbf{s}[i_l] = 1$, $\mathbf{w}[i_l] > 0$, $\mathbf{p}[i_{l+1}] = i_l$, and if $l \neq 0$, $i_l \neq 0$. Clearly, if $m > n$, there is one element $i_k \neq 0$ which appears twice in the path (pigeon hole principle). Hence we get in the path a cycle starting from i_k where 0 is not there. So, i_0 can't be reachable via parent links from i_k and in particular from i_m , this contradicts the existence of the current sequence.

Let a process i_l be given such that $\mathbf{w}[i_l] > 0$ and $\mathbf{s}[i_l] = 1$. According to invariant 13 at least one of the following should hold.

- There exists some i such that $i_l \in \mathbf{n}[i]$. By invariant 4, $i_l \neq i$. By the first part of $FC(n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$ it follows that $\mathbf{s}[i] \neq 1$. So, either $\mathbf{s}[i] = 2$, but this leads to a contradiction using invariant 10 (remember that $\mathbf{n}[i] \neq \emptyset$). Or, $\mathbf{s}[i] = 0$. By invariant 7, $i \in \mathbf{n}[i_l]$. So, by $FC(n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$, $\mathbf{s}[i_l] \neq 1$. Contradiction.
 - Or there is some i such that $\mathbf{p}[i] = i_l$, $i \neq 0$ and $\mathbf{s}[i] = 1$. By the second part of $FC(n, t, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$, we have $\mathbf{w}[i] > 0 \vee \mathbf{n}[i] \neq \emptyset$. By item 1 of this lemma, $\mathbf{n}[i] = \emptyset$. So $\mathbf{w}[i] > 0$. We can take $i_{l+1} = i$.
3. First, assume there is some process $i \neq 0$ such that $\mathbf{s}[i] = 1$. Using invariants 13, 15 and 14, it follows that there is a sequence of processes $i = i_0, \dots, i_m = 0$ such that, for all $0 \leq l < m$, $i_l \neq 0$ (even if it means to cut the path), $\mathbf{p}[i_l] = i_{l+1}$, $\mathbf{s}[i_l] = 1$ and $\mathbf{w}[i_{l+1}] > 0$. In particular $\mathbf{w}[0] > 0$ contradicting an assumption.

So, assume that there is no process $i \neq 0$ such that $\mathbf{s}[i] = 1$, but there is some process $i \neq 0$ such that $\mathbf{s}[i] = 0$. From the topology requirement it follows that there is a sequence $i = i_0, \dots, i_m = 0$ such that for all $0 \leq l < m$, $i_{l+1} \in \mathbf{n}_0[i_l]$. We show that $\mathbf{s}[i_l] = 0$ for all l , $0 \leq l \leq m$. This contradicts the assumption that $\mathbf{s}[0] = 1$.

Note that by assumption $\mathbf{s}[i_0] = 0$. So let i_l such that $\mathbf{s}[i_l] = 0$. By invariant 9, it follows that $i_{l+1} \in \mathbf{n}[i_l]$. By invariant 13, $\mathbf{w}[i_{l+1}] > 0$, so $i_{l+1} \neq 0$ and, by invariant 10, $\mathbf{s}[i_{l+1}] \neq 2$. As we have excluded that process i_{l+1} is in state 1, it must hold that $\mathbf{s}[i_{l+1}] = 0$, as required.

□

Below we copy the General Equality Theorem (see Theorem A.3) instantiated for the distributed summation algorithm. It says that, given the invariant, implementation *L-Impl*

and specification $L\text{-Spec}$ are equivalent (with or without a preceding τ -step, depending on whether the focus condition holds). Its proof requires that 6 groups of requirements, the so-called *matching criteria*, are checked. Given Lemma 6.1 this is completely straightforward.

Lemma 6.2. Assume $\text{goodtopology}(n, \mathbf{n}_0)$.

$$\begin{aligned} \text{Inv}(\mathbf{n}_0, \mathbf{t}_0, n, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) &\rightarrow \\ L\text{-Impl}(n, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) &\triangleleft FC(n, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) \triangleright \tau L\text{-Impl}(n, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) \\ &= \\ L\text{-Spec}(\mathbf{s}[0] = 1) &\triangleleft FC(n, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) \triangleright \tau L\text{-Spec}(\mathbf{s}[0] = 1) \end{aligned}$$

Proof. According to [8] it suffices to check that the following instances of the matching criteria are implied by the invariant.

1. By Lemma 4.1.1 $L\text{-Impl}$ is convergent.
2. The following three requirements ensure that the state mapping h is invariant under τ -steps of $L\text{-Impl}$.
 - (a) $\mathbf{s}[i] = 0 \wedge i \in \mathbf{n}[j] \wedge \mathbf{s}[j] = 1 \wedge i \neq j \wedge i \leq n \wedge j \leq n$ implies $\mathbf{s}[0] = (\mathbf{s}[i] := 1)[0]$ (note that $(\mathbf{s}[i] := 1)[0]$ is the first element of \mathbf{s} where the i^{th} element has been replaced by 1).
We distinguish two cases. If $i \neq 0$, the condition trivially holds because in that case $(\mathbf{s}[i] := 1)[0] = \mathbf{s}[0]$. If $i = 0$, one conjunct of the precondition says $\mathbf{s}[0] = 0$. This contradicts invariant 5.
 - (b) $\mathbf{s}[i] = 1 \wedge i \in \mathbf{n}[j] \wedge \mathbf{s}[j] = 1 \wedge i \neq j \wedge i \leq n \wedge j \leq n$ implies $\mathbf{s}[0] = \mathbf{s}[0]$.
This requirement clearly holds.
 - (c) $\mathbf{n}[j] = \emptyset \wedge \mathbf{w}[j] = 0 \wedge \mathbf{s}[j] = 1 \wedge \mathbf{s}[\mathbf{p}[j]] = 1 \wedge j \neq 0 \wedge j \neq \mathbf{p}[j] \wedge j \leq n \wedge \mathbf{p}[j] \leq n$ implies $\mathbf{s}[0] = (\mathbf{s}[j] := 2)[0]$.
This requirement is also trivially valid, because the assumption explicitly says $j \neq 0$. Hence, $(\mathbf{s}[j] := 2)[0] = \mathbf{s}[0]$.
3. Next, we verify that when the $\overline{\text{rep}}$ action is enabled in $L\text{-Impl}$, it is enabled in $L\text{-Spec}$: $\mathbf{n}[0] = \emptyset \wedge \mathbf{w}[0] = 0 \wedge \mathbf{s}[0] = 1$ implies $\mathbf{s}[0] = 1$. This is obviously true.
4. We must show that if $L\text{-Impl}$ is in a focus point (no internal actions enabled) and $L\text{-Spec}$ can perform a $\overline{\text{rep}}$ -action, $L\text{-Impl}$ can also perform the $\overline{\text{rep}}$ action:
 $FC(n, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s}) \wedge \mathbf{s}[0] = 1$ implies $\mathbf{n}[0] = \emptyset \wedge \mathbf{w}[0] = 0 \wedge \mathbf{s}[0] = 1$. This is a direct consequence of Lemma 6.1.2 and Lemma 6.1.1.
5. We must show that if the $\overline{\text{rep}}$ action is enabled in $L\text{-Impl}$ then the reported sum is equal to the sum reported in $L\text{-Spec}$: $\mathbf{n}[0] = \emptyset \wedge \mathbf{w}[0] = 0 \wedge \mathbf{s}[0] = 1$ implies $\mathbf{t}[0] = \text{sum}(\mathbf{t}_0)$. By invariant 16 we have $\text{sum}(\mathbf{t}_0) = \text{sum}_{0,1}(\mathbf{t}, \mathbf{s})$. By definition, $\text{sum}_{0,1}(\mathbf{t}, \mathbf{s})$ contains the sum of the $\mathbf{t}[i]$ values of all processes i that are not in state 2. By Lemma 6.1.3, only process 0 is not in state 2. Hence $\text{sum}(\mathbf{t}_0) = \text{sum}_{0,1}(\mathbf{t}, \mathbf{s}) = \mathbf{t}[0]$.

6. Finally, we have to show that the h -mapping commutes with the \overline{rep} action, i.e. $(s[0] := 2)[0] \neq 1$. This is easily seen to hold.

□

Theorem 6.3.

$$\text{goodtopology}(n, \mathbf{n}_0) \rightarrow \tau \tau_I \partial_H(DSum(n, \mathbf{t}_0, \mathbf{n}_0)) = \tau \overline{rep}(\text{sum}(\mathbf{t}_0)) \delta$$

where $I = \{st^*, ans^*\}$ and $H = \{st, ans, \overline{st}, \overline{ans}\}$. In the trivial case that process 0 has no neighbours, the τ 's at the left and right side of the equation may be omitted.

Proof. Apply Lemma 6.2 with \mathbf{t}_0 substituted for \mathbf{t} , \mathbf{n}_0 for \mathbf{n} , \mathbf{p}_0 for \mathbf{p} , \mathbf{w}_0 for \mathbf{w} and \mathbf{s}_0 for \mathbf{s} . This substitution reduces the invariant to \top . Furthermore, reduction of the term $FC(n, \mathbf{t}_0, \mathbf{n}_0, \mathbf{p}_0, \mathbf{w}_0, \mathbf{s}_0)$ leads to $\forall i i \notin \mathbf{n}_0[0]$. Thus we have

$$\begin{aligned} L\text{-Impl}(n, \mathbf{t}_0, \mathbf{n}_0, \mathbf{p}_0, \mathbf{w}_0, \mathbf{s}_0) \langle \forall i i \notin \mathbf{n}_0[0] \rangle & \tau L\text{-Impl}(n, \mathbf{t}_0, \mathbf{n}_0, \mathbf{p}_0, \mathbf{w}_0, \mathbf{s}_0) \\ & = \\ L\text{-Spec}(\top) \langle \forall i i \notin \mathbf{n}_0[0] \rangle & \tau L\text{-Spec}(\top). \end{aligned}$$

Hence we can conclude

$$\tau L\text{-Impl}(n, \mathbf{t}_0, \mathbf{n}_0, \mathbf{p}_0, \mathbf{w}_0, \mathbf{s}_0) = \tau L\text{-Spec}(\top)$$

by adding an initial τ if appropriate. We can conclude the stronger

$$L\text{-Impl}(n, \mathbf{t}_0, \mathbf{n}_0, \mathbf{p}_0, \mathbf{w}_0, \mathbf{s}_0) = L\text{-Spec}(\top)$$

in case $\forall i i \notin \mathbf{n}_0[0]$, i.e. in case process 0 has no neighbours.

By Lemma 4.1.3, we have $\tau \tau_I \partial_H(DSum(n, \mathbf{t}_0, \mathbf{n}_0)) = L\text{-Impl}(n, \mathbf{t}_0, \mathbf{n}_0, \mathbf{p}_0, \mathbf{w}_0, \mathbf{s}_0)$. We also have seen that $L\text{-Spec}(\top) = \overline{rep}(\text{sum}(\mathbf{t}_0)) \delta$. The theorem follows. □

7 Computer-checking the verification

The proof of Theorem 6.3 establishing the correctness of the distributed summation algorithm (DSA for short) has been computer checked with the theorem prover PVS (2.1 Test (patch level 2.399)).

We have first defined in PVS the general notion of linear process equations (LPEs), and formulated the General Equality Theorem A.3 which allows to prove equality between processes specified by LPEs (see Appendix A). Using this theorem we have given a complete formalization of the proof in PVS. We have not mechanically checked the proof of GET itself since it is part of the logical framework of μCRL and we therefore considered it as given for the verification of this particular distributed algorithm. Also, the linearisation of the protocol, i.e. Lemma 4.1.2, was not checked. We note that linearisation can be done mechanically [5]. The whole of the definitions, lemmas and proof-scripts can be obtained by mailing one of the authors.

The specification language of PVS is a higher-order typed logic ([13, 14, 16]), with many built-in types including booleans, integers, sequences, lists, etc. For example, $\text{upto}(i)$: $\text{TYPE} = \{s: \text{nat} \mid s \leq i\}$ is the subtype of the integers less or equal to i . New types may be added together with functions, tuples, records, predicate subtypes, abstract datatypes. Usually, a PVS specification consist of one or several theories. A theory can have parameters and can be imported by other theories (see [13]).

In the vernacular of PVS, the complete main theorem (Theorem 6.3), including the note on the "trivial case", is represented as follows (in order to make clear what the PVS code is, we typeset it in teletype font):

```

MAINTHM : THEOREM
  goodtopology =>
    seq(tau,Sol(L_Impl)(nb,to,no,po,wo,so))
      =
    seq(tau,seq(rep_(totsum(to)),delta))
  AND
  ((FORALL (i:upto(nb)) : not(member(i,no(0)))) =>
    Sol(L_Impl)(nb,to,no,po,wo,so)
      =
    seq(rep_(totsum(to)),delta))

```

where seq , rep_- , tau , delta represent respectively the sequential composition operator \cdot , $\overline{\text{rep}}$, τ and δ . $\text{Sol}(L_Impl)$ is the solution of the linear process equation L_Impl depicted in Table 1. The value nb is the number n of non-root processes in the network. The terms $\text{to}, \text{no}, \text{po}, \text{wo}, \text{so}$ stand respectively for the initial values t_0, n_0, p_0, w_0, s_0 , while $\text{totsum}(\text{to})$ stands for the sum of the values in t_0 . Finally, goodtopology correspond to the topology requirements $\text{goodtopology}(n, n_0)$. The values nb and $(t_0, n_0, p_0, w_0, s_0)$ have been introduced as constants in PVS and therefore do not appear in goodtopology .

In the following subsections we describe the formalisation of the proof of MAINTHM in PVS. First, we describe how the General Equality Theorem has been encoded. In subsection 7.2, the data of L_Impl and L_Spec , the initial values t_0, n_0, p_0, w_0, s_0 , and the topology are given. In the next subsection we show how the invariant property, i.e. Theorem 5.2, has been proven in PVS. In subsection 7.4 the proof of Lemma 6.1 is described. In the following subsection, we present the formalisation of the state mapping, the focus points and the matching criteria. We conclude the proof in subsection 7.6. Finally, in subsection 7.7, we discuss the formalisation in PVS.

7.1 The General Equality Theorem

We have devised the general notion of a linear process equation (LPE) depending on a data type D as a parameter in a theory $\text{LPES}[D:\text{TYPE}]$: THEORY (see Definition A.1 in Appendix A). This theory imports the theory THEDATA : THEORY which specifies the processes, actions and domains over which summation takes place in the definition of the LPEs. The set of LPEs has been defined as a type $\text{LPE}:\text{TYPE} = \dots$. Each element of this type corresponds to a linear process equation. Theorem A.3 mentions two LPEs of which the second one runs

over a set of actions from which τ has been removed. So, in the same theory, we have defined a subtype `ALPE: TYPE = ...` of the previous type, containing elements that are LPEs but from which the τ action has been removed. We do not provide the types `LPE` and `ALPE` here because their definition is somewhat unwieldy and not necessary to understand the main steps of the verification.

Then, in a new theory `THGET[DX,DY:TYPE]: THEORY`, Theorem A.3 has been introduced. Here the data types `DX` and `DY` are parameters of the theory `THGET` that can be instantiated with data types. Since the LPEs involved rely on different data types, the theory imports both `LPES[DX]` and `LPES[DY]`. This is actually the way in PVS to use polymorphic types. The invariant property, the focus points and the criteria occurring in Theorem A.3 have been translated into the theory as predicates. Theorem A.3 is then represented as an axiom as follows:

```
GET : AXIOM FORALL (lpox: LPE[DX],lpoy: ALPE[DY],h: [DX -> DY],
                   I: [DX -> bool]) : Invlpox(lpox,I) AND
  (forall (d: DX) : I(d) => Convx(lpox) and Crit2(lpox,d,h) and
                   Crit3(lpox,lpoy,d,h) and Crit4(lpox,lpoy,d,h) and
                   Crit5(lpox,lpoy,d,h) and Crit6(lpox,lpoy,d,h)) =>
  forall (d: DX) : I(d) =>
    condi(Sol(lpox)(d),FC(lpox,d),seq(tau,Sol(lpox)(d)))
    =
    condi(Sol(lpoy)(h(d)),FC(lpox,d),seq(tau,Sol(lpoy)(h(d))))).
```

Here, `condi(arg1,arg2,arg3)` denotes the *conditional* construct $arg1 \triangleleft arg2 \triangleright arg3$.

The invariant property `Invlpox(lpox:LPE[DX], I:[DX -> bool])` asserts that the function `I:[DX -> bool]` is an *invariant* of `lpox`, that is to say, for any state `d:DX`, if `I(d)` holds and a step can be performed by `lpox`, then `I` holds in the new state. The focus condition `FC(lpox:LPE[DX],d:DX)` characterises the states `d` of the LPE implementation `lpox` in which no τ -action is enabled. The first criterion `Convx(lpox:LPE[DX])` says that the LPE implementation `lpox` must be convergent. `Crit2(lpox:LPE[DX],d:DX,h:[DX -> DY])` says that if in a state `d` in the LPE implementation `lpox`, an internal step can be done, then this internal step is not observable modulo the state mapping `h`. `Crit3(lpox:LPE[DX],lpoy:LPE[DY],d:DX,h:[DX -> DY])` says that when the LPE implementation `lpox` can perform an external step according to the value of `d`, then the corresponding point (modulo `h`) in the LPE specification `lpoy` must also be able to perform this step. `Crit4(lpox:LPE[DX],lpoy:LPE[DY],d:DX,h:[DX -> DY])` says that in a focus point `FC(lpox,d)` of the LPE implementation `lpox`, an action can be performed if it is enabled in the LPE specification `lpoy`. `Crit5(lpox,lpoy,d,h)` and `Crit6(lpox,lpoy,d,h)` express that corresponding external actions carry the same data parameter (modulo `d` and `h`) and lead to corresponding states.

In order to define *L-Impl* and *L-Spec*, data types `DX` and `DY` corresponding to their parameters have been made explicit in a theory `IMPL: THEORY`. The theory `IMPL` imports the theories `LPES[DX]` and `LPES[DY]`. The distributed summation algorithm *L-Impl* has been defined as an LPE by `L_Impl: LPE[DX] = ...` corresponding to the formalisation of *L-Impl* depicted in Table 1. In the same way the linear process *L-Spec* described in Section 6 has been defined

to be of type ALPE, L.Spec: ALPE[DY] = ...

The various parts of the proof of MAINTHM are provided in the theories DSA1, DSA2, DSA3, DSA4 and DSA: THEORY.

7.2 The data types, the initial values and the topology

Below we give the data types DX and DY corresponding to the types of the parameters of *L-Impl* and *L-Spec*. Since PVS allows one to have bounded types using subtypes, we have used families indexed by the finite set of processes in a network. Here nb denotes the number of non-root processes, it has been introduced in the THEDATA theory:

```

nb          : nat
state       : TYPE = upto(2)
ent         : var nat
boundlist(ent) : TYPE = {l : list[upto(nb)] | length(l) <= ent}

% boundlist(ent) is a type parameterised by ent. It is used in particular
% to define auxiliary functions in the theories DSA2, DSA3.

intlist     : TYPE = [upto(nb) -> nat]
listlist    : TYPE = [upto(nb) -> boundlist(nb+1)]
boundintlist : TYPE = [upto(nb) -> upto(nb)]
statelist   : TYPE = [upto(nb) -> state]

DX          : TYPE = [nat, intlist, listlist, boundintlist, intlist, statelist]
DY          : TYPE = bool

```

The initial values t_0, n_0, p_0, w_0, s_0 of Definition 3.4 appear in the IMPL theory as follows:

```

to : intlist
no : listlist
po(i: upto(nb)) : upto(nb) = 0
wo(i: upto(nb)) : nat = length(no(i))
so(i: upto(nb)) : state = if i=0 then 1 else 0 endif

```

Here, e.g., the domain and range of w_0 are respectively $\text{upto}(nb)$ and nat , so the type of w_0 is intlist . For each element i of type $\text{upto}(nb)$, $w_0(i)$ is equal to $\text{length}(no(i))$. This corresponds to the fact that w_0 is a list of length $n + 1$, with at each position i the size of the set $n_0[i]$. Likewise, the domain and range of s_0 are respectively $\text{upto}(nb)$ and (a subset of) nat , hence the type of s_0 is statelist . Also, p_0 is the null function of type boundintlist .

The definition of boundintlist implies the fourth property of the topology in Definition 3.3. So it is not necessary to introduce it into goodtopology . On the other hand, we modified the topology with a new requirement TOP4 asserting that each element has at most one occurrence in $n_0[j]$ (*neighbours*). This is obviously true for sets but wrong for lists. We could also have used sets for *neighbours*, as used in the previous sections, but it is more convenient using lists together with this requirement. The requirement TOP4 allows us to have the following properties:

Member_three : LEMMA FORALL (i: upto(nb),l: boundlist(nb+1)) :
 not(member(i,rem(i,l)))

Lightlist_three : LEMMA FORALL (i: upto(nb),l: boundlist(nb+1)) :
 nodouble(l) and member(i,l) => length(l)=1+length(rem(i,l))

where *rem* removes all occurrences of *i* in *l*. The non-redundant property TOP4 is necessary to prove that the invariant predicate *Inv* applied to the initial values holds (for *Inv*, see subsection 7.3):

Initialinv : LEMMA goodtopology => Inv(nb,to,no,po,wo,so)

where below *goodtopology* is defined:

TOP1 : bool = FORALL (i: upto(nb)) : not (member(i,no(i)))

TOP2 : bool = FORALL (i,j: upto(nb)) : member(i,no(j)) iff member(j,no(i))

TOP3 : bool = FORALL (i: upto(nb)) : EXISTS (m: upto(nb),
 fm : [upto(m) -> upto(nb)]) :
 fm(0)=i) AND fm(m)=0) AND
 FORALL (l: upto(m)) : l < m => member(fm(l+1),no(fm(l)))

TOP4 : bool = FORALL (i: upto(nb)) : nodouble(no(i))

pretopology : bool = TOP1 and TOP2 and TOP3

goodtopology : bool = TOP1 and TOP2 and TOP3 and TOP4.

7.3 The invariant property

The use of the GET theorem requires an invariant property, that is to say the existence of a function $I: [DX \rightarrow \text{bool}]$ such that in particular the predicate $\text{Invlpox}(L_Impl, I)$ holds. For *I* we provide a function *Inv* which corresponds to the formalisation of the conjunction of the items in Theorem 5.2. Actually, the first three items of Theorem 5.2 are not included in *Inv*, as they are direct consequences of the definitions of *statelist*, *boundintlist* and *listlist*, respectively. In the proof of **MAINTHM**, the predicate $\text{Invlpox}(L_Impl, \text{Inv})$ leads to the requirement to prove the four predicates *S1Inv*, *S2Inv*, *S3Inv* and *S4Inv*, each one corresponding to a summand of the LPE *L-Impl* in Table 1. The predicate *S1Inv* corresponds to the summand with the \overline{rep} action, the remaining three predicates correspond to the summands with τ actions.

S1Inv: LEMMA FORALL (k: nat,t: intlist,n: listlist,p: boundintlist,
 w: intlist,s: statelist) :
 Inv(k,t,n,p,w,s) AND n(0)=null and w(0)=0 and s(0)=1 =>
 Inv(k,t,n,p,w,s with [(0):=2])

S2Inv : LEMMA FORALL (i,j: upto(nb),k: nat,t: intlist,n: listlist,
 p: boundintlist,w: intlist,s: statelist) :
 Inv(k,t,n,p,w,s) AND s(i)=0 and member(i,n(j)) and
 s(j)=1 and i/=j =>
 Inv(k,t,n with [(j):=rem(i,n(j))),(i):=rem(j,n(i))],
 p with [(i):=j],w with [(i):=minus(length(n(i)),1)],
 s with [(i):=1])

S3Inv : LEMMA FORALL (i,j: upto(nb),k: nat,t: intlist,n: listlist,
 p: boundintlist,w: intlist,s: statelist) :
 Inv(k,t,n,p,w,s) AND s(i)=1 and member(i,n(j)) and s(j)=1
 and i/=j =>
 Inv(k,t,n with [(j):=rem(i,n(j))],p,w with [(i):=minus(w(i),1)],s)

S4Inv : LEMMA FORALL (i,j: upto(nb),k: nat,t: intlist,n: listlist,
 p: boundintlist,w: intlist,s: statelist) :
 Inv(k,t,n,p,w,s) AND n(j)=null and w(j)=0 and s(j)=1 and
 s(p(j))=1 and j/=0 and j/=p(j) =>
 Inv(k,t with [(p(j)):=t(p(j))+t(j)],n,p,
 w with [(p(j)):=minus(w(p(j)),1)],s with [(j):=2]).

Each of the previous lemmas has been proven in the following way. First, we define predicates Inv4, ..., Inv16 corresponding to the items of Theorem 5.2. For example the last predicate is:

Inv16(k:nat,t:intlist,n:listlist,p:boundintlist,w:intlist,s:statelist):
 bool = s(0)/=2 => sum0and1(t,s)=totsum(to)

where $\text{sum0and1}(t,s)$ represents $\text{sum}_{0,1}(t,s)$ (Definition 5.1).

Secondly, for $i = 4, \dots, 16$, we introduced and proved lemmas S1Invi, S2Invi, S3Invi, and S4Invi (Inv is changed to Invi). As a detail, we mention that items 5 and 6 have been directly put into Inv13, as they are only necessary for the item 13 and easily checked. They obviously still appear in Inv15 because the proofs of S1Inv15, ..., S4Inv15 require respectively the lemmas S1Inv13, ..., S4Inv13. Likewise, item 11 has been directly put into Inv14. The most delicate to be proven was S2Inv13.

7.4 Lemma 6.1

The formalisation of Lemma 6.1 directly follows the text given in Section 6. So, it has been split into three lemmas Item1lemma6_1, Item2lemma6_1, and Item3lemma6_1. We present here only the first one.

Item1lemma6_1 : LEMMA FORALL (k: nat,t: intlist,n: listlist,
 p: boundintlist,w: intlist,s: statelist) :
 Inv(k,t,n,p,w,s) AND s(0)=1 =>
 FORALL (i: upto(nb)): FC2(k,t,n,p,w,s) AND s(i)=1 => n(i)=null

where FC2 defined below corresponds to the optimised focus condition FC introduced in Section 6.

```
FC2(k: nat,t: intlist,n: listlist,p: boundintlist,w: intlist,s: statelist):
bool = FORALL (i,j: upto(nb)) :
  (s(i)=2 or not(member(i,n(j)))) or s(j)/=1 or i=j)
  and
  (n(j)/=null or w(j)>0 or s(j)/=1 or s(p(j))/=1 or j=0).
```

- . Consider, for example, the following part of the proof of Item2lemma6.1, corresponding to Lemma 6.1.2. Under the hypotheses $Inv(\mathbf{n}_0, \mathbf{t}_0, \mathbf{n}, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$, $s[0] = 1$, $FC(\mathbf{n}, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$, $w[0] > 0$, we can construct for any integer m , a sequence of $m + 1$ processes $0 = i_0, i_1, \dots, i_m$ such that for all $0 \leq l \leq m$, $s[i_l] = 1$, $w[i_l] > 0$, $p[i_{l+1}] = i_l$, and if $l \neq 0$, $i_l \neq 0$.

The construction of the sequence is formalised by the lemma `ConstructSequel`. It turned out to be convenient to use the relation $p^h[i_0] = i_h$, i.e. i_h is the h^{th} successor of i_0 . Using the function `iterate`, $p^h[i_0] = i_h$ is modeled by `iterate(p,h)(i)`.

```
ConstructSequel : LEMMA FORALL (k: nat,t: intlist,n: listlist,
                                p: boundintlist,w: intlist,s: statelist) :
  Inv(k,t,n,p,w,s) and s(0)=1 =>
    FC2(k,t,n,p,w,s) and w(0)/=0 =>
  FORALL (m :nat) : EXISTS (i: upto(nb)) :
    iterate(p,m)(i)=0 and FORALL (h: nat) :
      (h<=m => s(iterate(p,h)(i))=1 and w(iterate(p,h)(i))/=0)
    and (h<m => iterate(p,h)(i)/=0).
```

Next, consider a step of the proof of Lemma 6.1.3 under the following assumptions:

$Inv(\mathbf{n}_0, \mathbf{t}_0, \mathbf{n}, \mathbf{t}, \mathbf{n}, \mathbf{p}, \mathbf{w}, \mathbf{s})$, $s[0] = 1$, $w[0] = 0$, the existence of a process $i \neq 0$ with $s[i] = 0$, and the existence of a sequence $i = i_0, \dots, i_m = 0$ such that for all $0 \leq l < m$, $i_{l+1} \in \mathbf{n}_0[i_l]$. We have to prove that $s[i_h] = 0$ for all h , $0 \leq h \leq m$. This is obtained via the following lemma:

```
BuiltNewSequel : LEMMA FORALL (k: nat,t: intlist,n: listlist,
                                p: boundintlist,w: intlist,s: statelist) :
  Inv(k,t,n,p,w,s) AND s(0)=1 AND w(0)=0 =>
  FORALL (i,m: upto(nb),fm: [upto(m) -> upto(nb)]):
    (i/=0 AND s(i)=0 AND fm(0)=i AND fm(m)=0 AND
  FORALL (l: upto(m)) : l < m => member(fm(l+1),no(fm(l))))
    => FORALL (h: upto(m)) : s(fm(h))=0
```

where $fm(h)$ stands for i_h . The proof of `BuiltNewSequel` requires in particular the fact that any process of the sequence mentioned above can't be in state 1. This is provided by the first step of the proof of Lemma 6.1.3, and corresponds to the following lemma:

```
StepforItem3 : LEMMA FORALL (k: nat,t: intlist,n: listlist,p: boundintlist,
                                w: intlist,s: statelist) :
  Inv(k,t,n,p,w,s) AND s(0)=1 AND w(0)=0 =>
  FORALL (i: upto(nb)) : i/=0 => s(i)/=1
```

On the whole, the formalised proof of `Item2lemma6.1` required 2 auxiliary definitions and 14 lemmas. Some of them were also used at other places, in particular for `Item3lemma6.1`, which required overall 6 lemmas.

7.5 State mapping, focus points and matching criteria

As explained in Section 6, the state mapping $h: [DX \rightarrow DY]$ occurring in the theorem `GET` is provided by the following function

```
stmapp(k:nat,t:intlist,n:listlist,p:boundintlist,w:intlist,s:statelist):
    bool = s(0)=1.
```

The application of the theorem `GET` in the proof of `MAINTHM` leads to following proof six obligations `Convx(L_Impl)`, `Crit2(L_Impl,d,stmapp)`, `Crit3(L_Impl,L_Spec,d,stmapp)`, ..., `Crit6(L_Impl,L_Spec,d,stmapp)` to be proven using the topological hypotheses and the invariant `Inv(d)`. Corresponding to these proof obligations, we define six predicates `criter1`, ..., `criter6` and introduce six lemmas `Invcriter1`, ..., `Invcriter6`. The predicates correspond respectively to the formalisation of the items given in the proof of Lemma 6.2. For example the fifth criterion is:

```
criter5(k:nat,t:intlist,n:listlist,p:boundintlist,w:intlist,s:statelist):
    bool = n(0)=null and w(0)=0 and s(0)=1 => t(0)=totsum(to)
```

The lemmas `Invcriter1`, ..., `Invcriter6` assert that each criterion holds under `Inv`. Note that `criter5` is the only criterion which requires the topological hypotheses:

```
Invcriter5 : LEMMA FORALL (k: nat,t: intlist,n: listlist,
    p: boundintlist,w: intlist,s: statelist) :
    pretopology and Inv(k,t,n,p,w,s) => criter5(k,t,n,p,w,s).
```

During the proof of `MAINTHM`, `Crit5(L_Impl,L_Spec,d,stmapp)` was smoothly reduced to proving `criter5(proj_1(d), ..., proj_6(d))` for which we could use the lemma `Invcriter5` mentioned above. The others were proven in the same way. As a detail, we mention that, whereas `Crit4(L_Impl,L_Spec,d,stmapp)` mentions the focus condition `FC(L_Impl,d)`, we use for its proof Lemma 6.1 which used the optimised focus condition `FC2(d)`. To bridge this gap, we provided an auxiliary focus point formula `FC1`, defined below, together with a lemma `FCequivFC1` which shows that `FC` is equivalent to `FC1`. Next we proved, assuming the invariant `Inv`, lemma `FC1equivFC2` which establishes the equivalence between `FC1` and `FC2` and so between `FC` and `FC2`.

```
FC1(k: nat,t: intlist,n: listlist,p: boundintlist,w: intlist,s: statelist):
    bool = (FORALL (i,j: upto(nb)) :
        not(s(i)=0 and member(i,n(j)) and s(j)=1 and i/=j))
    and (FORALL (i,j: upto(nb)) :
        not(s(i)=1 and member(i,n(j)) and s(j)=1 and i/=j))
    and (FORALL (i,j: upto(nb)) :
        not(n(j)=null and w(j)=0 and s(j)=1 and s(p(j))=1 and j/=0 and j/=p(j))).
```

Below we give the lemma `FC1equivFC2`. Actually, its proof require the following lemma `noclon` which is easily proven. It asserts that if i can reach to another process j via parent links, then i can't be its own parent.

```
FC1equivFC2 : LEMMA FORALL (k: nat,t: intlist,n: listlist,p: boundintlist,
                             w: intlist,s: statelist) :
  Inv(k,t,n,p,w,s) => (FC1(k,t,n,p,w,s) <=> FC2(k,t,n,p,w,s))
```

```
noclon : LEMMA FORALL (i,j: upto(nb),p: boundintlist,m: nat) :
  preach(i,j,p,m) and i/=j => p(i)/=i.
```

where `preach(i,j,p,m)` represents $Preach(i,j,p,m)$ (Definition 5.1).

7.6 Final steps of the proof

We finish the formal proof using the main steps of the previous subsections and we show how the last arguments of the proof of Theorem 6.3 given in Section 6 have been translated in PVS.

The first required step before applying the theorem `GET` is to make sure that `L_Impl` and `L_Spec` are linear process equations. This is the same as establishing that they are respectively of the types `LPE` and `ALPE`. In other words, the `LPE`s properties arise as types correctness conditions.

As Theorem 6.3 is a consequence of the General Equality Theorem A.3, we find on the top of the proof commands tree of `MAINTHM` the two following commands (`LEMMA "GET"`) introducing the theorem `GET` in the proof of `MAINTHM`, and (`INST -1 "L_Impl" "L_Spec" "stmapp" "Inv"`) instantiating the quantifiers of `GET`. Next, the hypothesis `goodtopology` in `MAINTHM` has been put as an antecedent in the sequent formalizing the main theorem. Finally the assumptions of `GET` have been split off, providing the following formula

```
forall (d: DX) : Inv(d) =>
  condi(Sol(L_Impl)(d),FC(L_Impl,d),seq(tau,Sol(L_Impl)(d)))
  =
  condi(Sol(L_Spec)(stmapp(d)),FC(L_Impl,d),seq(tau,Sol(L_Spec)(stmapp(d))))
```

as an antecedent from which we derive the main theorem below, and returning the formulas `Invlpox(L_Impl,Inv)` and

```
forall (d: DX) : Inv(d) => Convx(L_Impl) and Crit2(L_Impl,d,stmapp) and
  Crit3(L_Impl,L_Spec,d,stmapp) and Crit4(L_Impl,L_Spec,d,stmapp) and
  Crit5(L_Impl,L_Spec,d,stmapp) and Crit6(L_Impl,L_Spec,d,stmapp)
```

of `GET` as two new proof obligations. The first one of these has been proved as described in subsection 7.3. Next, we have skolemised the second formula, moved the hypothesis `Inv` as antecedent and split the resulting formula into six sequents. Each of them could be proven as described in subsection 7.5.

This leaves the main sequent to be proved. The quantified variable d in the antecedent coming from `GET` mentioned above was instantiated with `(nb,to,no,po,wo,so)`. The lemma

Initialinv : LEMMA goodtopology => Inv(nb,to,no,po,wo,so)

gives Inv(nb,to,no,po,wo,so), which allows to reduce the antecedent coming from GET into the following one:

$$\begin{aligned} & \text{condi}(\text{Sol}(\text{L_Impl})(\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so}), \text{FC}(\text{L_Impl}, (\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so})), \\ & \quad \text{seq}(\text{tau}, \text{Sol}(\text{L_Impl})(\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so}))) \\ & \quad = \\ & \text{condi}(\text{Sol}(\text{L_Spec})(\text{stmapp}(\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so})), \text{FC}(\text{L_Impl}, (\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so})), \\ & \quad \text{seq}(\text{tau}, \text{Sol}(\text{L_Spec})(\text{stmapp}(\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so}))))). \end{aligned}$$

Next, we used the stmapp function, the so value, and Sol(L_Spec) together with the μCRL axioms to obtain

$$\begin{aligned} & \text{condi}(\text{Sol}(\text{L_Impl})(\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so}), \text{FC}(\text{L_Impl}, (\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so})), \\ & \quad \text{seq}(\text{tau}, \text{Sol}(\text{L_Impl})(\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so}))) \\ & \quad = \\ & \text{condi}(\text{seq}(\text{rep}_-(\text{totsum}(\text{to})), \text{delta}), \text{FC}(\text{L_Impl}, (\text{nb},\text{to},\text{no},\text{po},\text{wo},\text{so})), \\ & \quad \text{seq}(\text{tau}, \text{seq}(\text{rep}_-(\text{totsum}(\text{to})), \text{delta}))). \end{aligned}$$

We then proceeded with a case distinction between FC(L_Impl, (nb,to,no,po,wo,so)) being true and false, respectively. Finally, we introduced the following lemma:

ReduceFC : LEMMA pretopology =>
(FC2(nb,to,no,po,wo,so) iff FORALL (i:upto(nb)) : not(member(i,no(0))))

This allowed us to establish MAINTHM and therefore to finish the proof: Q.E.D.

7.7 Discussion

The distributed summation algorithm has been computer checked with on the whole 134 lemmas. Apart from the *Type Correctness Conditions (T.C.C.s)* concerning the LPEs L_Impl and L_Spec, this does not take into account the OBLIGATIONS lemmas, since these were generated automatically by PVS for the T.C.C.s so did not have to be devised, and were always immediately proven. The complete proof development (definitions, lemmas including OBLIGATION lemmas also, and proof scripts) comprises about 270 Kb.

The expressive power of the PVS system allowed us to translate the definitions and lemmas in an accurate way. However it turned out that it was difficult to translate the general notion of a linear process equation (LPE). The reason is that its definition is complex and polymorphic, involving data types as parameters. In particular a family of a priori different types indexed by a finite set of actions appears in the LPEs. This phenomenon also occurs in the matching criteria of the General Equality Theorem. Therefore we have explicitly introduced a number bounding the size of the set of actions which allowed us to use record types for LPEs instead of functional definitions.

As mentioned at the beginning of this section, the theorem GET has been provided as an axiom in PVS and, being part of the meta-theory of μCRL , was not mechanically checked itself. We point out that the theorem MAINTHM has been proven without any axioms other

than an axiom stating that \overline{rep} action and τ action are distinct, those of μCRL and GET within the logical framework of PVS.

As has been illustrated with the distributed summation algorithm, we think that the syntactical and axiomatic description in μCRL of distributed systems is suitable for verification and enables the proofs to be checked by higher order proof checkers or theorem provers such as PVS and COQ leading to an extremely high level of confidence in the correctness of the proofs.

8 Comparison with other verifications.

Our appraisal of the applicability of formal techniques for reasoning about distributed algorithms differs strongly from Chou's. We feel that proof techniques from the area of formal methods are sufficiently mature to prove the correctness of protocols of at least the complexity of a distributed summation algorithm. We are convinced that the reader – after having read, digested and understood the correctness proof – will agree that it is straightforward and not at all more complex than necessary.

There are as far as we know three other formal proofs of the distributed summation algorithm. In [18] Vaandrager proves the summation algorithm correct in the setting of I/O automata. His description of the algorithm, which is best compared to the linearisation of the algorithm in Table 1, differs from ours in two aspects. First, in his set-up processes communicate asynchronously by means of queues, whereas we let processes communicate using synchronous interaction. The second difference is that in [18] when a process reads a \overline{st} message from its input queue, \overline{st} messages are put simultaneously in all outgoing queues, whereas in our setting sending these messages happens in an interleaved way.

The structure of Vaandrager's proof is the following. First, some invariants are proven. Using these, a relation is defined between implementation and specification that is proven to be a refinement. From this it may be concluded that the trace set of the implementation is included in the trace set of the specification. As trace inclusion does not imply deadlock-freeness, this fact is proven separately.

There are two major differences between both proofs. In [18] history and prophecy variables are employed which are not present in our paper. It is remarked in [18] that it should be possible to give the proof without such auxiliary variables, but that they have been included to illustrate their use. Secondly, although the refinement that is presented is very much like our state mapping h , we establish branching bisimulation between specification and the algorithm, whereas using the refinement, only a weaker fact, namely trace inclusion is shown. Therefore, we do not have to show deadlock freeness separately, as branching bisimulation preserves deadlock freeness.

It is also important to note the similarities between both proofs. The overall structure of the proofs is the same, as are the essential arguments. Actually, it would not be very hard to upgrade the proofs of trace inclusion and deadlock freeness in [18] to imply a result such as ours.

The description of the algorithm by Chou [2] closely resembles the description of [18]. Chou's proof sets out with defining three modal properties together stating that the algorithm will deliver the total sum exactly once. First, it is argued that proving the modal properties

directly on the description of the distributed summation algorithm is too complicated. Then a more abstract version of the algorithm is defined in terms of causes and events, the state space of which can be characterised by simple invariants. The abstract version is related to the original one by means of a simulation relation and a ‘joint invariant’. It is shown that translated versions of the modal correctness properties hold for the abstract version. Using the simulation relation and the joint invariant it is shown that validity of the original correctness properties can be derived for the original algorithm. Chou’s proof thus is similar to Vaandrager’s proof except that correctness is stated by means of modal properties instead of by a specification automaton, and the abstract version is defined in terms of causes and events. To the best of our knowledge, these proofs have not been proof-checked.

We remark that our proof method is purely syntactical and axiomatic, while the proofs in [2, 18] have a semantical nature. This is not very visible in this paper, as we have for readability omitted all syntactic definitions of data types and employ the General Equality Theorem from [8] whose proof is syntactical but which has a semantic flavour. We feel that our method shares the advantages of semantical reasoning, while its axiomatic nature allows a complete, computer-checked formalisation.

A third proof of essentially the same description of the protocol as the one of Chou and Vaandrager is given by Hesselink [9]. He describes the protocol using LISP functions that are triggered by data in input queues and atomically put data in all output queues of a process. In order to model non-deterministic behaviour, Hesselink introduces an oracle. He then proves that the protocol terminates and that if terminated the total sum is collected in the root. These observations exactly match with proof steps one and five of Lemma 6.2. Hesselink uses the Boyer-Moore theorem prover to verify the correctness of his proofs.

A Short description of μCRL

The language μCRL is a formalism (with proof theory) for process algebra comprising data [7, 6]. In this section we give a brief overview of the μCRL syntax for processes and restate the General Equality Theorem of [8], which is the basis of the correctness proof in this paper. In order to do the latter we have to define the format for linear process equations.

A.1 Overview of syntax

Starting from a set Act of actions that can be parameterised with data, processes are defined by means of guarded recursive equations and the following operators.

First, there is a constant δ ($\delta \notin \text{Act}$) that cannot perform any action and is called deadlock or inaction.

Next, there are the sequential composition operator \cdot and the alternative composition operator $+$. The process $x \cdot y$ first behaves as x and if x successfully terminates continues to behave as y . The process $x + y$ can either do an action of x and continue to behave as x or do an action of y and continue to behave as y .

Interleaving parallelism is modeled by the operator \parallel . The process $x \parallel y$ is the result of interleaving actions of x and y , except that actions from x and y may also synchronise to a communication action, when this is explicitly allowed by a communication function. This is a partial, commutative and associative function $\gamma : \text{Act} \times \text{Act} \rightarrow \text{Act}$ that describes how actions

can communicate; parameterised actions $a(d)$ and $b(d')$ communicate to $\gamma(a, b)(d)$, provided $d = d'$. A specification of a process typically contains a specification of a communication function.

In order to axiomatise the parallel operator there are two auxiliary parallel operators. First, the left merge \ll , which behaves as the parallel operator, except that the first step must come from the process at the left. Secondly, the communication merge $|$ which also behaves as the parallel operator, except that the first step is a communication between both arguments, as specified by the communication function γ . We often write $a | b = c$ for $\gamma(a, b) = c$.

To enforce that actions in processes x and y synchronise, we can prevent actions from happening on their own, using the encapsulation operator ∂_H . The process $\partial_H(x)$ can perform all actions of x except that actions in the set H are blocked. So, assuming $\gamma(a, b) = c$, in $\partial_{\{a, b\}}(x \parallel y)$ the actions a and b are forced to synchronise to c .

We assume the existence of a special action τ ($\tau \notin \text{Act}$) that is internal and cannot be directly observed. The hiding operator τ_I renames the actions in the set I to τ . By hiding all internal communications of a process only the external actions remain.

The following two operators combine data with processes. The sum operator $\Sigma_{d:D} p(d)$ describes the process that can execute the process $p(d)$ for some value d selected from the sort D . The conditional operator $_{\leftarrow \triangleright}$ describes the *then-if-else*. The process $x \leftarrow b \triangleright y$ (where b is a boolean) has the behaviour of x if b is true and the behaviour of y if b is false. When the right hand side trivialises, i.e. y equals δ , we write $[b] \Rightarrow x$.

We apply the convention that \cdot binds stronger than Σ , followed by $_{\leftarrow \triangleright}$, the parallel operators, and $+$ binds weakest. Moreover, \cdot is usually suppressed.

We work in the setting of branching bisimulation [17], which is a refinement of weak bisimulation [11].

Axioms for the operators can be found, e.g., in [7].

A.2 Linear process equations

The process equations for process P in Definition 3.1 and for $L\text{-Impl}$ in Table 1 are (essentially) written in the format of *linear process equations* (LPEs). A linear process equation is of the form $X(d:D) = \text{RHS}$, where d is a parameter of type D and RHS consists of an alternative composition of a number of summands of the form

$$\sum_{e:E} [b(d, e)] \Rightarrow a(f(d, e)) X(g(d, e))$$

Such a summand means that if for some e of type E the guard $b(d, e)$ is satisfied, the action a can be performed with parameter $f(d, e)$, followed by a recursive call of X with new value $g(d, e)$. Now the main feature of LPEs is that for each action there is a most one summand in the alternative composition¹. This makes it possible to describe LPEs by means of a finite set Act of actions as indices, giving for each action a the set E_a over which summation takes place, the guard b_a that enables the action, the function f_a that determines the data parameter of the action and the function g_a that determines the value of the recursive call.

In the next definition the symbol Σ , used for summation over data types, is also used to describe an alternative composition over a finite set of actions. If $\text{Act} = \{a_1, \dots, a_n\}$, then

¹The LPEs described here, are called *deterministic* in [8].

$\sum_{a \in Act} p_a$ denotes $p_{a_1} + p_{a_2} + \dots + p_{a_n}$. Note that for summation over actions the symbol \in is used (instead of the symbol $:$).

Definition A.1. Let $Act \subseteq Act \cup \{\tau\}$ be a finite set of actions, and let D be a data type. A *linear process equation (LPE)* over Act and D is an equation of the form

$$X(d : D) = \sum_{a \in Act} \sum_{e : E_a} [b_a(d, e)] \Rightarrow a(f_a(d, e)) X(g_a(d, e)).$$

for some data types E_a, D_a , and functions $f_a : D \rightarrow E_a \rightarrow D_a$, $g_a : D \rightarrow E_a \rightarrow D$, $b_a : D \rightarrow E_a \rightarrow \mathbf{Bool}$. (We assume that τ has no parameter.) \square

The process equations for process P in Definition 3.1 and for $L\text{-Impl}$ in Table 1 do not directly fit in the LPE format; consult [8] to verify that the deviations are harmless.

Definition A.2. An LPE X written as in Definition A.1 is called *convergent* if it does not admit infinite τ -paths, i.e., there is a well-founded ordering $<$ on D such that for all $e : E_\tau$ and $d : D$ we have that $b_\tau(d, e)$ implies $g_\tau(d, e) < d$.

An *invariant* of an LPE X written as in Definition A.1 is a function $I : D \rightarrow \mathbf{Bool}$ such that for all $a \in Act$, $e : E_a$, and $d : D$ we have $b_a(d, e) \wedge I(d) \rightarrow I(g_a(d, e))$. \square

For each LPE X , we assume an axiom which postulates that X has a solution, and an axiom that postulates that every *convergent* LPE has at most one solution. In this way, convergent LPEs define processes. The two principles reflect that we only consider process algebras where every LPE has at least one solution and converging LPEs have precisely one solution.

A.3 General Equality Theorem

Theorem A.3 (General Equality Theorem from [8]). *Let X and Y be LPEs given as follows:*

$$X(d : D_X) = \sum_{a \in Act} \sum_{e : E_a} [b_a(d, e)] \Rightarrow a(f_a(d, e)) X(g_a(d, e))$$

$$Y(d : D_Y) = \sum_{a \in Act \setminus \{\tau\}} \sum_{e : E_a} [b'_a(d, e)] \Rightarrow a(f'_a(d, e)) Y(g'_a(d, e))$$

Let FC_X be a formula over $d : D_X$ describing exactly the states of X from which no τ -action is enabled (i.e. equivalent to $\neg \exists x : E_\tau b_\tau(d, x)$). Assume that r and q are solutions of X and Y , respectively. Suppose I is an invariant of X and, for all $d : D_X$, $I(d)$ implies the following set of matching criteria.

$$X \text{ is convergent} \tag{1}$$

$$\forall e : E_\tau (b_\tau(d, e) \rightarrow h(d) = h(g_\tau(d, e))) \tag{2}$$

$$\forall a \in Act \setminus \{\tau\} \forall e : E_a (b_a(d, e) \rightarrow b'_a(h(d), e)) \tag{3}$$

$$\forall a \in Act \setminus \{\tau\} \forall e : E_a (FC_X(d) \wedge b'_a(h(d), e) \rightarrow b_a(d, e)) \tag{4}$$

$$\forall a \in Act \setminus \{\tau\} \forall e: E_a(b_a(d, e) \rightarrow f_a(d, e) = f'_a(h(d), e)) \quad (5)$$

$$\forall a \in Act \setminus \{\tau\} \forall e: E_a(b_a(d, e) \rightarrow h(g_a(d, e)) = g'_a(h(d), e)) \quad (6)$$

Then

$$\forall d: D_X \ I(d) \rightarrow r(d) \triangleleft FC_X(d) \triangleright \tau \ r(d) = q(h(d)) \triangleleft FC_X(d) \triangleright \tau \ q(h(d)).$$

References

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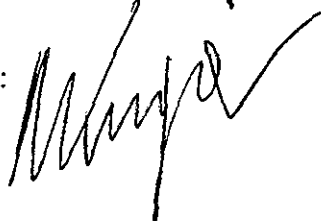
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